

Claims 1-35 have been cancelled.

36. (new) A method of creating a visual presentation on a substantially plane large surface by means of at least one free-roaming marking device, comprising the steps of:

passing along at least one trajectory on said surface with said free-roaming marking device, in such a way that at least one contour line of said visual presentation is passed on said surface, and

treating said surface along said at least one contour line of said visual presentation by means of said free-roaming marking device when passing along said at least one trajectory.

37. (new) The method according to claim 36, wherein said treating step comprises marking said surface with an exchangeable tool, wherein said tool is adapted to deposit paint onto the surface and along said at least one contour line.

38. (new) The method according to claim 36, wherein said treating step comprises marking said surface with an exchangeable tool, wherein said tool is adapted to perform at least one task chosen from bending and/or orienting and/or cutting grass blades in said surface.

39. (new) The method according to claim 36, further comprising the steps of:

subsequently treating at least one interior or exterior area delineated by said contour lines of said visual presentation on said surface.

40. (new) The method according to claim 39, wherein said areas are treated by means of said free-roaming marking device.

41. (new) The method according to claim 39, wherein said areas are manually treated.

42. (new) The method according to claim 36, further comprising the steps of:

said trajectories from a source data representing said visual presentation, wherein said source data is a computer data file representing said visual presentation, and automatically transforming said computer file to instructions for said free-roaming marking device to pass along said trajectories for creating said visual presentation.

43. (new) The method according to claim 42, wherein said computer data file is a vector graphics file.

44. (new) The method according to claim 42, wherein said instructions comprise working operations of the free-roaming marking device comprising working order, direction, speed, trajectory track and start/stop positions of the free-roaming marking device, colour and marking on/off.

45. (new) The method according to claim 36, further comprising the steps of:

said visual presentation according to scale, and adapting said visual presentation to a viewing angle and/or viewing distance with respect to a position of an image capturing means in relation to said visual presentation of said surface.

46. (new) The method according to claim 45, wherein adapting the perspective of said visual presentation created on said surface to said viewing angle and distance, comprising adapting the visual presentation with regard to size, shape or contrast.

47. (new) The method according to claim 45, wherein the image capturing device is a TV-camera.

48. (new) The method according to claim 36, wherein said visual presentation is an all-over visual presentation.

49. (new) The method according to claim 36, wherein the visual presentation is selected from the group comprising: drawings or images comprising logotypes or artwork.

50. (new) The method according to claim 36, wherein the free-roaming marking device determines its position by means of a navigation system.

51. (new) The method according to claim 50, wherein said navigation system is a laser scanner and/or a GPS unit.

52. (new) The method according to claim 36, characterized in that said treating step comprises marking said contour lines by depositing paint on said surface and/or bending of grass along said contour lines.

53. (new) The method according to claim 36, wherein the surface material is selected from the group comprising: asphalt, concrete, cement, stone, natural stone, a textile

fabric, a synthetic material, artifical surface material, rubber, metal, glass blocks and grass.

54. (new) The method according to claim 36, wherein
5 said surface is selected from the group comprising: an
airport runway, a road surface, a roof surface, an
athlectic field surface, sports fields, outdoor carpets,
synthetic surfaces, artifical surfaces, container surfaces,
wherein these surfaces are outdoor and/or indoor surfaces.
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55. (new) The method according to claim 36, wherein
said surface is pre-treated with a foundation for
formatting said surface.

56. (new) A system for performing the method of claim
15 36 by generating visual presentations on large surfaces,
said system comrising a free-roaming marking device adapted
to create said visual presentations by treating said
surface, wherein said free-roaming marking device in use is
20 adapted to pass along trajectories on said surface, said
free-roaming device comprising treatment means for treating
said surface along contour lines of said visual
presentation when passing along said trajectories, and
calculation means for automatically calculating said
25 trajectories from a source data representing said visual
presentation.

57. (new) The system according to claim 56, further
comprising a portable computing device for wireless
30 communication with the free-roaming marking device and for
programming and controlling the free-roaming marking device
on location where the visual presentation is to be created.

58. (new) The system according to claim 57, further
35 comprising a remote computer for creating a master for said
visual presentation and wherein said master is transmitted
to said portable computing device for further processing.

59. (new) The system according to claim 56, wherein said free-roaming marking device automatically creates at least one contour line of said visual presentation on said large surface with said marking means.

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60. (new) The system according to claim 59, wherein said marking means is at least one paint depositing nozzle.

61. (new) The system according to claim 60, wherein
10 said at least one nozzle is arranged on a nozzle carrier on said free-roaming marking device.

62. (new) The system according to claim 61, wherein
15 said nozzle carrier is centrally arranged in relation to a rotational center of said free-roaming device or arranged on a side of said free-roaming device.

63. (new) The system according to claim 61, wherein
20 said nozzle carrier is arranged in front of or behind said free-roaming device.

64. (new) The system according to claim 56, wherein
25 said free-roaming marking device comprises a surface treatment tool having an adjustable treatment direction and an adjustable pressure onto said surface.

65. (new) The system according to claim 56, wherein
30 said free-roaming marking device comprises a navigation system.

66. (new) The system according to claim 65, wherein
said navigation system is a laser scanner and/or a GPS unit.

67. (new) A computer-readable medium having embodied
35 thereon a computer program for processing by a computer for generating a visual presentation on a large surface according to the method of claim 36, said computer program

comprising a plurality of code segments, characterized by a first code segment for computing trajectories along which a free-roaming marking device passes for creating said visual presentation, wherein said trajectories are automatically
5 computed from a source data representing said visual presentation.

68. (new) The computer-readable medium according to claim 67, further characterized by a second code segment
10 for instructing said free-roaming marking device to pass along trajectories on said surface in such a way that at least one contour line of said visual presentation is created on said large surface by treating said surface along contour lines of said visual presentation with said
15 free-roaming marking device when passing along said trajectories.

69. (new) Use of a mobile robot as a free-roaming marking device for performing the method according to claim
20 36, by generating a visual presentation on a large surface, wherein said mobile robot is instructed to pass along trajectories, and said visual presentation is created on said surface as a sum of said trajectories, wherein at least one contour line of said visual presentation is
25 created on said surface by treating said surface along contour lines of said visual presentation with said free-roaming marking device when passing along said trajectories.

30 70. Use of a mobile robot according to claim 69, wherein said trajectories are automatically calculated from a computer data file comprising a graphics file storing said visual information of said visual presentation.